

## CLAIMS

1. (Amended) A legged mobile robot having a body and legs whose upper ends are connected to the body and whose lower ends are each connected to a foot to be movable when the legs are driven,

5 characterized in that:

the foot comprises:

a foot main body connected to each of the legs;

a toe provided at a fore end of the foot main body to be bendable with respect to the foot main body; and

10 a bending angle holder capable of holding a bending angle of the toe in a bendable range of the toe from zero degree at which a contact area of the foot becomes maximum to a predetermined degree, the bending angle holder holding the toe at the bending angle comprising one from among the zero degree, the predetermined degree and an arbitrary angle between the zero degree and the predetermined angle.

15 2. The legged mobile robot according to claim 1, further including;  
a bending angle change suppressor that suppresses change of the bending angle of the toe.

3. The legged mobile robot according to claim 1 or 2, wherein the toe is made continuous with the foot main body and is made of an elastic material that bends with flexing.

20 4. The legged mobile robot according to claim 1 or 2, wherein the toe is connected to the fore end of the foot main body through a rotational shaft capable of rotating about a pitch axis.

5. The legged mobile robot according to claim 4, further including:  
25 an urging means for urging the toe in a direction of restoring it to an initial position.

6. The legged mobile robot according to any of claims 1 to 5, wherein the bending angle holder comprises a friction brake.

7. The legged mobile robot according to any of claims 2 to 6, wherein the

bending angle change suppressor comprises a damper.

8. The legged mobile robot according to any of claims 2 to 5, wherein the bending angle holder and the bending angle change suppressor comprise a friction brake